

### AMENDMENTS TO THE CLAIMS

Please add or amend the claims to read as follows, and cancel without prejudice or disclaimer claims indicated as cancelled. The following Listing of Claims is intended to replace all prior versions and/or listings of claims in the application:

#### Listing of Claims:

1. **(Currently Amended)** An active noise control system for controlling noise produced by a noise source, said system comprising:  
an acoustic sensor to sense a noise pattern and to produce a noise signal corresponding to the sensed noise pattern;  
an estimator to produce a predicted noise signal by applying an estimation function to said noise signal; and  
an acoustic transducer to produce a noise destructive pattern based on said predicted noise signal,  
wherein the noise destructive pattern ~~produced by the acoustic transducer~~ has a non-linear relationship to the noise pattern sensed by the acoustic ~~sensor~~ sensor,  
wherein the noise destructive pattern is fully adaptive,  
wherein the noise destructive pattern comprises a fully adaptive nonlinear component,  
wherein the acoustic sensor comprises a plurality of acoustic sensor units correlated to said noise source;
2. **(Original)** The system of claim 1, wherein said estimator is able to adapt one or more parameters of said estimation function based on a noise error at a predetermined location.
3. **(Original)** The system of claim 2, wherein said noise error comprises an anticipated destructive interference between said noise pattern and said noise destructive pattern at said predetermined location.
4. **(Original)** The system of claim 2 comprising an error-sensing microphone to sense said noise error at said predetermined location.

5. **(Original)** The system of claim 2 comprising an error evaluator to evaluate said noise error based on said noise signal and said predicted noise signal.
6. **(Original)** The system of claim 5, wherein said error evaluator comprises:  
a speaker transfer function module to produce an estimation of said noise destructive pattern by applying a speaker transfer function to said predicted noise signal;  
a modulation transfer function module to produce an estimation of said noise pattern at said predetermined location by applying a modulation transfer function to said noise signal; and  
a subtractor to subtract the estimation of said noise destructive pattern from the estimation of said noise pattern.
7. **(Original)** The system of claim 2, wherein said estimator is able to adapt said one or more parameters based on a predetermined criterion.
8. **(Original)** The system of any one of claim 7, wherein said estimator is able to reduce said error value by adapting said one or more parameters.
9. **(Original)** The system of claim 8, wherein said adaptive estimator is able to minimize said error value by adapting said one or more parameters.
10. **(Original)** The system of claim 2, wherein said one or more parameters comprise at least one parameter selected from the group consisting of a center parameter, an effective radius parameter, and an intensity parameter.
11. **(Original)** The system of claim 10, wherein said estimator is able to adapt said center parameter based on the following equation:

$$c_k(n+1) = c_k(n) - \mu_e e(n) w_k \sum_{s=0}^{S-1} STF(s) f_k[n-s] \left( \frac{1}{v_k} \sum_{i=0}^{L-1} (x(n-i) - c_k(i)) \right)$$

wherein  $c_k(n+1)$  denotes an adapted value of said center parameter,  
 $c_k(n)$  denotes a current value of said center parameter,  
 $w_k$  denotes said intensity parameter,  
 $L$  denotes a predetermined number of samples of said noise signal,  
 $STF$  denotes a predetermined speaker transfer function,  
 $S$  denotes a predetermined speaker transfer function frequency parameter,  
 $\mu_c$  denotes a predetermined convergence parameter corresponding to said center parameter,  
 $\gamma_k$  denotes said effective radius parameter,  
 $e(n)$  denotes said noise error,  
 $f_k$  denotes a predetermined function, and  
 $x(n)$  denotes an  $n$ -th sample of said noise signal.

12. **(Original)** The system of claim 10, wherein said estimator is able to adapt said effective radius parameter based on the following equation:

$$v_k(n+1) = v_k(n) - \mu_v e(n) w_k \sum_{s=0}^{S-1} STF(s) f_k[n-s] \frac{1}{(v_k)^2} \sum_{i=0}^{L-1} (x(n-i) - c_k(i))^2$$

wherein  $\gamma_k(n+1)$  denotes an adapted value of said effective radius parameter,  
 $\gamma_k(n)$  denotes a current value of said effective radius parameter,  
 $w_k$  denotes said intensity parameter,  
 $L$  denotes a predetermined number of samples of said noise signal,  
 $STF$  denotes a predetermined speaker transfer function,  
 $S$  denotes a predetermined speaker transfer function frequency parameter,  
 $\mu_\gamma$  denotes a predetermined convergence parameter corresponding to said effective radius parameter,  
 $c_k$  denotes said center parameter,  
 $e(n)$  denotes said noise error,  
 $f_k$  denotes a predetermined function, and  
 $x(n)$  denotes an  $n$ -th sample of said noise signal.

13. **(Original)** The system of claim 10, wherein said estimator is able to adapt said intensity parameter based on the following equation:

$$w_k(n+1) = w_k(n) - \mu_w e(n) \sum_{s=0}^{S-1} STF(s) f_k[n-s]$$

wherein  $w_k(n+1)$  denotes an adapted value of said intensity parameter,

$w_k(n)$  denotes a current value of said intensity parameter,

$w_k$  denotes said intensity parameter,

$L$  denotes a predetermined number of samples of said noise signal,

$STF$  denotes a predetermined speaker transfer function,

$S$  denotes a predetermined speaker transfer function frequency parameter,

$\mu_w$  denotes a predetermined convergence parameter corresponding to said intensity parameter,

$f_k$  denotes a predetermined function, and

$x(n)$  denotes an  $n$ -th sample of said noise signal.

14. **(Currently Amended)** The system of claim 1, wherein said estimation function comprises a non-linear estimation ~~function~~ function,  
wherein the estimator is able to estimate a noise error corresponding to an anticipated destructive interference between a pattern of the noise and the noise destructive pattern at a predetermined location, wherein said predetermined location is distinct from a location of said acoustic sensor.
15. **(Original)** The system of claim 14, wherein said non-linear function comprises a radial basis function
16. **(Currently Amended)** The system of claim 1, wherein said acoustic sensor comprises a microphone, and wherein the noise destructive pattern produced by the acoustic transducer has an exponential relationship to the noise pattern sensed by the acoustic sensor.

17. **(Currently Amended)** The system of claim 1, wherein said acoustic transducer comprises a ~~speaker~~, speaker,  
wherein said acoustic sensor comprises an array of two or more microphones,  
wherein the two or more microphones are located in two or more, respective, locations,  
wherein the two or more microphones are adapted to achieve coherence between the  
sensed noise pattern and the noise produced by the noise source, by taking into account  
at least one or more of:  
geometric structure of a path between said microphones and the noise source;  
aerodynamic attributes of the path between said microphones and the noise  
source;  
surface roughness along the path between said microphones and the noise source;  
turbulent airflow along the path between said microphones and the noise source;  
formation of acoustic signals along the path between said microphones and the  
noise source.
18. **(Currently Amended)** An active noise control system for controlling a noise produced by a noise source, said system comprising:  
a primary acoustic sensor to sense a noise pattern and to produce a corresponding primary noise signal;  
at least one secondary acoustic sensor to sense a residual noise pattern and to produce at least one secondary noise signal corresponding to the residual noise pattern sensed by said at least one secondary acoustic sensor, respectively,  
wherein said at least one secondary acoustic sensor is separated from said noise source by a distance larger than a distance between said primary acoustic sensor and said noise source; and  
a controller functionally associated with an acoustic transducer and a primary estimator to produce a predicted noise signal,  
wherein said controller is adapted to produce a noise destructive pattern based on said primary noise signal and said at least one secondary noise signal and said predicted noise ~~signal~~, signal,  
wherein the noise destructive pattern produced by the controller has a non-linear relationship to the noise pattern sensed by the primary acoustic ~~sensor~~, sensor,

wherein the noise destructive pattern is fully adaptive,  
wherein the noise destructive pattern comprises a fully adaptive nonlinear component,  
wherein the primary acoustic sensor comprises a plurality of acoustic sensor units  
correlated to said noise source;

19. **(Original)** The system of claim 18, wherein said primary estimator is adapted to produce a predicted primary signal by applying a primary estimation function to said primary noise signal; and further comprising at least one secondary estimator to produce at least one predicted secondary signal by applying at least one secondary estimation function to said at least one secondary noise signal, respectively.
20. **(Original)** The system of claim 19, wherein said primary estimator is able to iteratively adapt one or more parameters of said primary estimation function based on a noise error.
21. **(Original)** The system of claim 19, wherein said at least one secondary estimator is able to iteratively adapt one or more parameters of said at least one secondary estimation function, respectively, based on a noise error.
22. **(Original)** The system claim 19, wherein said controller is able to control said acoustic transducer based on a combination of said predicted primary signal and said at least one predicted secondary signal.
23. **(Original)** The system of claim 22, wherein said controller is able to control said acoustic transducer based on the sum of said predicted primary signal and said at least one predicted secondary signal.
24. **(Currently Amended)** The system claim 20, wherein said controller comprises a noise error evaluator to evaluate ~~said a noise error~~; error corresponding to an anticipated destructive interference between a pattern of the noise and the noise destructive pattern at a predetermined location, wherein said predetermined location is distinct from locations of said primary and secondary acoustic sensors.

25. **(Original)** The system of claim 24, wherein said noise error evaluator is able to evaluate said noise error based on said primary noise signal, said at least one secondary noise signal and said predicted primary signal.
26. **(Original)** The system of claim 25, wherein said noise error evaluator comprises:  
a speaker transfer function module to produce an estimation of a primary part of said noise destructive pattern corresponding to said predicted primary signal by applying a speaker transfer function to said predicted primary signal;  
a modulation transfer function module to produce an estimation of said noise pattern by applying a modulation transfer function to a combination of said primary noise signal and said at least one secondary noise signal; and  
a subtractor to subtract the estimation of the primary part of said noise destructive pattern from the estimation of said noise pattern.
27. **(Original)** The system of claim 24, wherein said controller comprises at least one residual noise evaluator to evaluate at least one residual noise.
28. **(Original)** The system of claim 27, wherein said at least one residual noise evaluator is able to evaluate said residual noise based on said noise error and said at least one predicted secondary signal, respectively.
29. **(Previously Presented)** The system of claim 28, wherein said residual error evaluator comprises:  
a speaker transfer function module to produce an estimation of a secondary part of said noise destructive pattern corresponding to said predicted secondary signal by applying a speaker transfer function to said predicted secondary signal; and  
a subtractor to subtract the estimation of the secondary part of said noise destructive pattern from said noise error.

30. **(Previously Presented)** The system of claim 18, wherein at least one of said primary acoustic sensor and said at least one secondary acoustic sensor comprises a microphone, and wherein the noise destructive pattern produced by the acoustic transducer has an exponential relationship to the noise pattern sensed by the primary acoustic sensor.
31. **(Currently Amended)** The system of claim 18, wherein said acoustic transducer comprises a ~~speaker~~, speaker,  
wherein said primary acoustic sensor comprises an array of two or more microphones,  
wherein the two or more microphones are located in two or more, respective, locations,  
wherein the two or more microphones are adapted to achieve coherence between the  
sensed noise pattern and the noise produced by the noise source, by taking into account  
at least one or more of:  
geometric structure of a path between said microphones and the noise source;  
aerodynamic attributes of the path between said microphones and the noise  
source;  
surface roughness along the path between said microphones and the noise source;  
turbulent airflow along the path between said microphones and the noise source;  
formation of acoustic signals along the path between said microphones and the  
noise source.